

MS ISSUE FEE
PATENT
1781-0224P

IN THE U.S. PATENT AND TRADEMARK OFFICE

Applicant: Kok Kiong TAN et al. Conf.: 4272
Appl. No.: 09/840,040 Group: 2834
Filed: April 24, 2001 Examiner: J. Jones
For: ADAPTIVE RIPPLE SUPPRESSION/COMPENSATION
APPARATUS FOR PERMANENT MAGNET LINEAR MOTORS

L E T T E R

Commissioner for Patents
P.O. Box 1450
Alexandria, VA 22313-1450

January 16, 2004

Sir:

Under the provisions of 35 U.S.C. § 119 and 37 C.F.R. § 1.55(a), the applicant(s) hereby claim(s) the right of priority based on the following application(s):

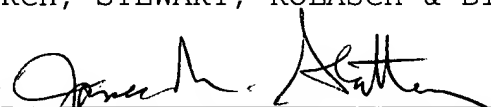
<u>Country</u>	<u>Application No.</u>	<u>Filed</u>
SINGAPORE	200002284-8	April 25, 2000


A certified copy of the above-noted application(s) is(are) attached hereto.

If necessary, the Commissioner is hereby authorized in this, concurrent, and future replies, to charge payment or credit any overpayment to Deposit Account No. 02-2448 for any additional fee required under 37 C.F.R. §§ 1.16 or 1.17; particularly, extension of time fees.

Respectfully submitted,

BIRCH, STEWART, KOLASCH & BIRCH, LLP

By 
James M. Slattery, #28,380


JMS/CTT/ags

P.O. Box 747
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Attachment(s)

(Rev. 09/30/03)



Image

52830
MS ISSUE FEE
PATENT
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IN THE U.S. PATENT AND TRADEMARK OFFICE

Applicant: Kok Kiong TAN et al. Conf.: 4272
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For: ADAPTIVE RIPPLE SUPPRESSION/COMPENSATION
APPARATUS FOR PERMANENT MAGNET LINEAR MOTORS

**PETITION FOR LATE ENTRY OF PRIORITY CLAIM
AND/OR PRIORITY PAPERS UNDER 37 C.F.R. § 1.55(a)**

Commissioner for Patents
P.O. Box 1450
Alexandria, VA 22313-1450

January 16, 2004

Sir:

Applicant petitions for entry of the following accompanying papers with respect to the priority claim in this case being made after payment of the issue fee on January 9, 2004.

X Certified Copy(ies) of the application from which priority is claimed:

01/21/2004 DTESSEM1 00000069 09840040

01 FC:1460

130.00 OP

Country
SINGAPORE

Application No.
200002284-8

Filed
April 25, 2000


FEE


The Petition fee (37 C.F.R. § 1.17(i)) of \$130 is attached hereto.

If necessary, the Commissioner is hereby authorized in this, concurrent, and future replies, to charge payment or credit any overpayment to Deposit Account No. 02-2448 for any additional fee required under 37 C.F.R. §§ 1.16 or 1.17; particularly, extension of time fees.

Respectfully submitted,

BIRCH, STEWART, KOLASCH & BIRCH, LLP

By 
James M. Slattery, #28,380


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Attachment(s)

(Rev. 09/30/03)

KOK KIONG TAN et al.
09/840,040, Filed: 4/24/01
ADAPTIVE RIPPLE SUPPRESSION
COMPENSATION

**REGISTRY OF PATENTS
SINGAPORE**


This is to certify that the annexed is a true copy of specification as filed for the following Singapore patent application.

Date of Filing : 25 APRIL 2000

Application Number : 200002284-8

Applicant(s) /
Proprietor(s) of
Patent : NATIONAL UNIVERSITY OF
SINGAPORE
GINTIC INSTITUTE OF
MANUFACTURING TECHNOLOGY

Title of Invention : AN ADAPTIVE RIPPLE
SUPPRESSION/COMPENSATION
APPARATUS FOR PERMANENT
MAGNET LINEAR MOTORS



TAN KAR LENG (Ms)
Assistant Registrar
for REGISTRAR OF PATENTS

PATENTS FORM 1

Rule 19

**SINGAPORE
PATENTS ACT
(CHAPTER 221)
PATENTS RULES**

*The Registrar of Patents
Registry of Patents*

**200002284-8
25 APR 2000**

**REQUEST FOR THE GRANT OF A PATENT
THE GRANT OF A PATENT IS REQUESTED BY THE UNDERSIGNED ON THE BASIS OF THE PRESENT
APPLICATION**

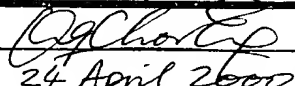
I. Title of Invention	An Adaptive Ripple Suppression/ Compensation Apparatus for permanent Magnet Linear Motors	
II. Applicant(s) (See note 2)	(a) Name	National University of Singapore
	Body Description/ Residency	Incorporated in Singapore
	Street Name & Number	National University of Singapore 10 Kent Ridge Crescent
	City	Singapore 119260
	State	Singapore
	Country	Singapore
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	City	Singapore 638075
	State	Singapore
	Country	Singapore
	(c) Name	
	Body Description/ Residency	
	Street Name & Number	
	City	
	State	
	Country	

6/49

200002284-8

III. Declaration of Priority (see note 3)	Country/Country Designated		File no.	
	Filing Date			
	Country/Country Designated		File no.	
	Filing Date			
	Country/Country Designated		File no.	
	Filing Date			
IV. Inventors (See note 4)				
(a) The applicant(s) is/are the sole/joint inventor(s).		<div style="display: flex; justify-content: space-around;"> <div> <input type="checkbox"/> Yes <input checked="" type="checkbox"/> No </div> <div> <input checked="" type="checkbox"/> Yes <input type="checkbox"/> No </div> </div>		
(b) A statement on Patents Form 8 is/will be furnished.				
V. Name of Agent (if any) (See note 5)				
VI. Address for Service (See note 6)	Block/Hse No		Level No	
	Unit No/PO Box	Kent Ridge PO Box 1016	Postal Code	911101
	Street Name			
	Building Name			
VII. Claiming an earlier filing date under section 20(3), 26(6) or 47(4). (See note 7)	Application No			
	Filing Date			
	[Please tick in the relevant space provided]: () Proceeding under rule 27(1)(a). Date on which the earlier application was amended = _____ or () Proceeding under rule 27(1)(b).			

200002284-8

VIII. Invention has been displayed at an International Exhibition (See note 8)	<input type="checkbox"/> Yes <input checked="" type="checkbox"/> No	
IX. Section 114 requirements (See note 9)	The invention relates to and/or used a micro-organism deposited for the purposes of disclosure in accordance with section 114 with a depository authority under the Budapest Treaty. <input type="checkbox"/> Yes <input checked="" type="checkbox"/> No	
X. Check List (To be filled in by applicant or agent)	A. The application contains the following number of sheet(s):-	
	1. Request	4 sheets
	2. Description	11 sheets
	3. Claim(s).	2 sheets
4. Drawing(s).	3 sheets	
5. Abstract.	1 sheets	
B. The application as filed is accompanied by:-		
1. Priority document	<input type="checkbox"/>	
2. Translation of priority document	<input type="checkbox"/>	
3. Statement of Inventorship & right to grant	<input checked="" type="checkbox"/>	
4. International Exhibition Certificate	<input type="checkbox"/>	
XI. Signature(s) (See note 10)	Applicant (a)	
	Date	24 April 2000
	Applicant (b)	
	Date	
	Applicant (c)	
	Date	

200002284-8

NOTES:

1. This form when completed, should be brought or sent to the Registry of Patents together with the prescribed fee and 3 copies of the description of the invention, and of any drawings.
2. Enter the name and address of each applicant in the spaces provided at paragraph II. Names of individuals should be indicated in full and the surname or family name should be underlined. The names of all partners in a firm must be given in full. The place of residence of each individual should also be furnished in the space provided. Bodies corporate should be designated by their corporate name and country of incorporation and, where appropriate, the state of incorporation within that country should be entered where provided. Where more than 3 applicants are to be named, the names and address of the fourth and any further applicants should be given on a separate sheet attached to this form together with the signature of each of these further applicants.
3. The declaration of priority at paragraph III should state the date of the previous filing, the country in which it was made, and indicate the file number, if available. Where the application relied upon in an International Application or a regional patent application e.g. European patent application, one of the countries designated in that application [being one falling under the Patents (Convention Countries) Order] should be identified and the name of that country should be entered in the space provided.
4. Where the applicant or applicants is/are the sole inventor or the joint inventors, paragraph IV should be completed by marking the 'YES' Box in the declaration (a) and the 'NO' Box in the alternative statement (b). Where this is not the case, the 'NO' Box in declaration (a) should be marked and a statement will be required to be filed on Patents Form 8.
5. If the applicant has appointed an agent to act on his behalf, the agent's name should be indicated in the spaces available at paragraph V.
6. An address for service in Singapore to which all documents may be sent must be stated at paragraph VI. It is recommended that a telephone number be provided if an agent is not appointed.
7. When an application is made by virtue of section 20(3), 26(6) or 47(4), the appropriate section should be identified at paragraph VII and the number of the earlier application or any patent granted thereon identified. Applicants proceeding under section 26(6) should identify which provision in rule 27 they are proceeding under. If the applicants are proceeding under rule 27(1)(a), they should also indicate the date on which the earlier application was amended.
8. Where the applicant wishes an earlier disclosure of the invention by him at an International Exhibition to be disregarded in accordance with section 14(4)(c), then the 'YES' Box at paragraph VIII should be marked. Otherwise the 'NO' Box should be marked.
9. Where in disclosing the invention the application refers to one or more micro-organisms deposited with a depository authority under the Budapest Treaty, then the 'YES' Box at paragraph IX should be marked. Otherwise the 'NO' Box should be marked.
10. Attention is drawn to rules 90 and 105 of the Patent Rules. Where there are more than 3 applicants, see also Note 2 above.
11. Applicants resident in Singapore are reminded that if the Registry of Patents considers that an application contains information the publication of which might be prejudicial to the defence of Singapore or the safety of the public, it may prohibit or restrict its publication or communication. Any person resident in Singapore and wishing to apply for patent protection in other countries must first obtain permission from the Singapore Registry of Patents unless they have already applied for a patent for the same invention in Singapore. In the latter case, no application should be made overseas until at least 2 months after the application has been filed in Singapore.

For Official Use

Application Filing Date: / /

Request received on : / /

Fee received on : / /

Amount :

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**Delete whichever is inapplicable*

An adaptive ripple suppression/compensation apparatus for permanent magnet linear motors

Field of the Invention

5 The invention generally relates to the field of motion control, and more particularly to an adaptive ripple suppression/compensation design which enhances the tracking performance of high precision motion control systems such as those based on permanent magnet linear motors (PMLM).

Background of the Invention

10 Among the electric motor drives, permanent magnet linear motors (PMLM) are probably the most naturally suited to applications involving high speed and high precision motion control. The increasingly widespread industrial applications of PMLMs in various semiconductor processes, precision metrology and miniature system assembly are self-evident
15 testimonies of the effectiveness of PMLMs in addressing the high requirements associated with these application areas. The main benefits of a PMLM include the high force density achievable, low thermal losses and, most importantly, the high precision and accuracy associated with the simplicity in mechanical structure. Unlike rotary machines, linear motors require no indirect coupling
20 mechanisms as in gear box, chain and screw couplings. This greatly reduces the effects of contact-type non-linearities and disturbances such as backlash and frictional forces, especially when they are used with aerostatic or magnetic bearings. However, the advantages of using mechanical transmission are also consequently lost, such as the inherent ability to reduce the effects of model
25 uncertainties and external disturbances. Therefore, a reduction of these effects, either through proper physical design or via the control system, is of paramount importance if high-speed and high precision motion control is to be achieved.

 A significant and well-known nonlinear effect in the dynamics of the PMLM is the phenomenon of force ripple arising from the magnetic structure
30 which exhibit characteristics that are position and velocity dependent. This is a prominent factor limiting the performance of PMLMs. Periodic disturbances also occur in a variety of engineering applications. In data storage systems, for example, the eccentricity of the track on a disk requires a periodic movement of

the read/write head at the frequency of the rotation of the disk. In the rotary type DC motors and stepper motors, torque pulsations occur at the frequency of rotation of the motors, due to the tendency of the permanent magnets to align themselves along directions of minimum reluctance. In switched reluctance
 5 motors, torque ripples also arise due to the saturation effect and the variation of magnetic reluctance leading to highly nonlinear characteristics which result in the ripples.

A great deal of effort has been devoted to overcome the difficulties associated with the nonlinear rippling effects. Among the prior art, H_∞ optimal
 10 feedback control has been suggested to provide a high dynamic stiffness to external disturbances (D.M. Alter and T.C. Tsao, Control of linear motors for machine tool feed drives: design and implementation of H_∞ optimal feedback control ASME J. of Dynamic systems. Measurement and Control, vol. 118, pp649-658, 1996). A neural-network feed-forward controller has also been
 15 proposed to reduce positional inaccuracy due to reproducible and slowly time-varying disturbances (G. Otten, T.J.A.de Vries, J.van Amerongen, A.M.Rankers and E.W.Gaal, Linear motor motion control using a learning forward controller, IEEE/ASME Trans. on Mechatronics, vol.2(3), pp179-187, 1997). Yao and Tomizuka have proposed an adaptive robust control approach and applied it
 20 subsequently to high speed, high accuracy motion control of machine tools (B. Yao and M. Tomizuka, Adaptive robust control of SISO nonlinear systems in a semi-strict feedback form, Automatica, vol. 33(5), pp.893-900, 1997.). A radial-basis function has been proposed by Tan et al as part of a composite control scheme to reduce errors arising from nonlinear uncertain remnants
 25 which were not considered in the linear control (K.K. Tan, S. N. Huang, H. F. Dou, S.Y. Lim, S. J. Chin, Adaptive Robust Motion Control for Precise Trajectory Tracking Applications, Mechatronics - submitted, 1999.). Iterative learning control has also been proposed in the past, where it has been targeted at applications involving repeated iterative operations (K.K.Tan, T.H.Lee,
 30 S.Y.Lim, and H.F.Dou, Learning enhanced motion control of permanent magnet linear motor, Proc. of the third IFAC International Workshop on Motion Control, Grenoble, France, pp397-402, 1998.). In all these works,

while the efforts were geared towards the compensation of nonlinear uncertainties, there has been no explicit modelling of the ripple force phenomenon, and consequently, no direct approach to attempt to suppress these forces which should yield direct improvement in tracking performance.

5 Summary of the Invention

According to a first aspect the present invention a control system for controlling a plant having an operating characteristic which describes the translation of a plant input to a plant output, wherein the plant characteristic has a linear component and a non-linear component, the control system
10 comprising a feedback control function, and a feed-forward control function, such that a demand signal is simultaneously applied to respective inputs of the feedback and feed-forward control functions and respective outputs of the feedback and feed-forward control functions are summed together to generate the plant input, the feed-forward control function having a first component
15 which is a function of a model of the linear component of the plant characteristic, and a second component which is an adaptive function to compensate for the non-linear component of the plant characteristic, and the adaptive function being approximately modelled on the non-linear component of the plant characteristic and having adaptive laws which vary parameters of
20 the adaptive function with time such that the adaptive function approaches the non-linear component of the plant characteristic.

In a preferred embodiment of the invention, the non-linear component of the plant characteristic is of the form:-

$$u_{ripple} = A(x)\sin(ax + \phi) = A_1(x)\sin(ax) + A_2(x)\cos(ax),$$

25 where x is the plant variable,
and where the adaptive function has the form:-

$$u_{AFC} = a_1(x(t))\sin(ax) + a_2(x(t))\cos(ax),$$

where

$$\dot{a}_1(x(t)) = -ge\sin(ax),$$

30 $\dot{a}_2(x(t)) = -ge\cos(ax),$

e is an error signal given by:-

$$e = (x_d - x),$$

g is an adaptation gain and is greater than 0, x_d is the desired function of the plant variable and ω is related to 1/period of the non-linear component of the plant characteristic, such that the adaptive feed-forward control function
 5 continuously adjusts the parameters a_1 & a_2 in response to the error signal e .

One example of the type of plant to be controlled by an embodiment of the invention is a permanent magnet linear motor (PMLM), in which the plant variable x represents an instantaneous position of a translator of the linear motor, the desired function of the plant variable x_d represents the desired
 10 trajectory of the translator and the PMLM has a magnetic structure having a pole pitch x_p , such that $\omega = 2\pi/x_p$. In embodiments of this type, the adaptation gain has a value of in the range of 0-1, and preferably in the range of 0.2-0.6. Values of around 0.2 have been found to work well in practice, but other types of motor will require different values of adaptive gain for best
 15 performance.

In the preferred embodiment, the inputs to the ripple suppressor include a user specification of the pole pitch of the permanent magnet, the desired motion trajectory and the actual position measurement. These parameters allow the construction of a model for the ripple characteristics in terms of a
 20 sinusoidal function with respect to the displacement of the translator of the PMLM. The function of the preferred ripple suppressor is to continuously adjust the amplitude of the sinusoidal function based on the tracking error so that the ripple model approaches the actual characteristics optimally. The output from the ripple suppressor is a feed-forward control signal to be input to
 25 the PMLM which will compensate the ripple force accordingly. This input is in addition to other control input which the PMLM may already be receiving from the commissioned motion control system.

Preferably, the feedback controller is a Proportional/Integral/Derivative or, 3-term controller, hereinafter referred to
 30 as a PID controller.

The preferred embodiments of the invention provide a ripple suppression/compensation apparatus which can yield improvement in the tracking performance of servo mechanisms with a more specific view towards application to a PMLM. Because of its adaptive characteristics, it is applicable
 5 to different versions of PMLM without necessitating a change in the physical design.

Embodiments of the invention facilitate smooth precise motion while uncompromising on the maximum force achievable

Brief Description of the Drawings

10 An embodiment of the invention will now be described by way of example, with reference to the accompanying drawings, in which:

Figure 1 is a block diagram of a typical prior art motion control structure, PID-Proportional-Integral-Derivative, FFC-FeedForward Control;

Figure 2 is a block diagram of an embodiment of a control system
 15 according to the present invention, PID-Proportional-Integral-Derivative, FFC-FeedForward Control, AFC-Adaptive Feedforward Control;

Figure 3 is a graphical representation of control system signals, showing the tracking ability of an example of a system, such as that of Figure 2, according to the present invention, in which Figure 3(a) shows a signal
 20 representing a desired trajectory x_d , Figure 3(b) represents the error signal $(x_d - x)$, and Figure 3(c) represents the control signal provided at the input of the plant and derived by summing the outputs of the PID Controller, the Feed Forward Controller and the Adaptive Feed Forward Controller; and

Figure 4 is a graphical representation of control system signals, showing
 25 the tracking ability of a system without the adaptive feed forward component of the present invention in which Figure 3(a) again represents a signal representing a desired trajectory x_d , Figure 3(b) represents the error signal $(x_d - x)$, and Figure 3(c) represents the control signal U provided at the input of the plant and derived by summing the outputs of the PID Controller, the Feed
 30 Forward.

Detailed Description of the Preferred Embodiments

Referring to Figures 1 and 2, block diagrams are provided of two control systems for a permanent magnet linear motor. The figure 1 system is a prior art system employing feedback and feed-forward control, whereas the Figure 2 system is an illustrative embodiment of the present invention and employs adaptive feed-forward control (AFC) as well as feed-forward control (FFC), and feedback control (FBC) which in this example is a Proportional/Integral/Derivation (PID) controller.

Traditionally, where systems required an output state to be accurately controlled, adjusted and maintained at a predetermined value, feedback control systems were employed to continually adjust input to the system being controlled in order to maintain the required output. Typically, such feedback systems measured an output parameter 16 known as the measured variable or plant variable and compared it with a desired value 11 of that variable to calculate an error signal 18.

It is common in single loop feedback systems to employ Proportional/Integral/Derivative (PID) controllers 19 (also known as 3-term controllers) which have as their input, the error signal (e) 18 and have as their output a control signal (u_{PID}) 20 given by:

$$u_{PID} = -k_1 e + k_2 \int e dt + k_3 \frac{de}{dt}$$

where k_1 , k_2 & k_3 are constants chosen for the particular plant.

The principle of feed-forward control is that if the characteristics of the device to be controlled are modelled, the model may be used to predict the input required to obtain a desired change in output. By applying a demand signal 11, representing the desired system output to the input of the feed-forward controller 12, a component 13 is added to the PID controller output 20 to produce signal 14 of the device 15 being controlled such that, assuming perfect modelling, the output 16 should be caused to change to the desired output. Unfortunately, it is rarely possible to perfectly model a physical device, and therefore, feed-forward control cannot replace the traditional feedback control systems, but, merely supplement them. Feed-forward control, can

however, significantly improve system response by quickly adjusting the plant input for rapidly changing demand signals. To achieve similar response with a traditional feedback controller, would require high loop gains and would increase the possibility of instability. With non-linear systems, these problems are even more evident and the advantages of feed-forward control even greater, however, it is often not possible to model non-linear systems with sufficient accuracy, particularly when the non-linear response characteristic of the plant being controlled is a function of manufacturing tolerances of the plant. To deal with these shortcomings of conventional feed-forward control, it is now proposed to employ a form of adaptive feed-forward control which broadly models the non-linear characteristics of the plant being controlled, but includes an adaptive function that continuously adjusts the feed-forward parameters.

In Figure 2, the system input 11 is fed to the adaptive feed-forward controller (AFC) 21 as is the error signal 18 and the AFC 21 processes these inputs to produce its own control signal component (u_{AFC}) 22 which is added to the other control signals 13, 20 to produce the plant input 24.

In the case of a PMLP, the non-linear characteristic is primarily due to the force ripple phenomenon described previously. In the preferred embodiment the force ripple phenomenon is viewed and modelled as a response to a virtual input to the PMLM described in the form of a periodic sinusoidal signal:

$$u_{ripple} = A(x) \sin(ax + \phi) = A_1(x) \sin(ax) + A_2(x) \cos(ax), \quad (1)$$

where $\omega = \frac{2\pi}{x_p}$ and x_p is the pole pitch of the magnet structure. ϕ is the phase specification providing a reference point to the sinusoidal function. $A(x)$, $A_1(x)$ and $A_2(x)$ are functions of the displacement x of the translator of the linear motor.

A dither signal is thus designed correspondingly to eradicate this virtual force as:

$$u_{AFC} = a_1(x(t)) \sin(ax) + a_2(x(t)) \cos(ax). \quad (2)$$

Perfect cancellation will be achieved when

$$a_1^*(x) = -A_1(x), a_2^*(x) = -A_2(x). \quad (3)$$

Feed-forward compensation schemes are well known to be sensitive to modelling errors which inevitably result in significant remnant ripples. An adaptive approach is thus adopted so that a_1 and a_2 will be continuously adapted based on desired trajectories and prevailing tracking errors.

Let

$$a = \begin{bmatrix} a_1(x) \\ a_2(x) \end{bmatrix}, \theta = \begin{bmatrix} \sin(ax) \\ \cos(ax) \end{bmatrix}, a^* = \begin{bmatrix} -A_1(x) \\ -A_2(x) \end{bmatrix}. \quad (4)$$

The plant output due to AFC is then given by:

$$x_a = P[a - a^*]^T \theta, \quad (5)$$

where P denotes the plant.

(5) falls within the standard framework of adaptive control theory. Possible update laws for the adaptive parameters will therefore be:

$$\begin{aligned} \dot{a}_1(x(t)) &= -ge \sin(ax), & (6) \\ \dot{a}_2(x(t)) &= -ge \cos(ax), & (7) \end{aligned}$$

where $g > 0$ is an arbitrary adaptation gain, $e = x_d - x$ is the tracking error where x_d is the desired position trajectory.

Differentiating (13) and (14) with respect to time, the following equations are obtained

$$\dot{a}_1(t) = -ge\dot{x}_d \sin(ax), \quad (8)$$

$$\dot{a}_2(t) = -ge\dot{x}_d \cos(ax), \quad (9)$$

In other words, the adaptive update laws (8) and (9) can be applied as an adjustment mechanism such that $a_1(t)$ and $a_2(t)$ in (2) converge to their true values.

Implementation

As described above, the physical implementation of the ripple suppression/compensation apparatus is preferably by means of a microprocessor/digital-computer using known techniques to implement various aspects of the above described function. However, as will be appreciated by those of ordinary skills in the art, analog electronic circuits may be used to fulfil many parts of this purpose.

For the preferred digital implementation of the control apparatus, an interface between the(digital) controller apparatus and the analog (input) measurements and actuator (output) signals uses analog-to-digital and digital-to-analog converters, respectively, in the same manner as used by conventional digital controllers. Accordingly, the present disclosure omits description of such converters. Similarly, the functions of the ripple suppressor/compensator are implemented as a software program (stored in a Programmable Read Only Memory of the microprocessor/digital-computer, for example) for processing the stored data representing the converted input and output signals. The input parameter set, time functions and other data variables are held in the Random Access Memory of the microprocessor/ digital computer. The software used for this purpose by the present invention is the same as in other digitally implemented controllers and, accordingly, a detailed description thereof is omitted.

Experimental example

In this experimental example, a Linear Drive tubular linear motor (LD3810) was employed. The test bed system was equipped with a Renishaw optical encoder with an effective resolution of $17m$. The dSPACE control environment and rapid prototyping system was used, employing the DS1102 board.

The desired trajectories used in this experiment are given by:

$$x_d(\tau) = 10^6 [x_0 + (x_0 - x_f)(15\tau^4 - 6\tau^5 - 10\tau^3)], \quad (10)$$

$$\dot{x}_d(\tau) = 10^6 (x_0 - x_f)(60\tau^3 - 30\tau^4 - 30\tau^2), \quad (11)$$

where 10^6 is used to normalize the system units to μm . x_d and \dot{x}_d denote the desired position and velocity trajectories, $x_0 = 0$ and $x_f = 0.21m$ denote the initial and final positions, respectively. $\tau = t/(t_f - t_0)$, where $t_0 = 2$ seconds and $t_f = 5$ seconds are the initial time and final time of the trajectory.

5 As with feedback control, the gain (g) chosen for the adaptive feed-forward controller will be a trade off between lower values which give reliable performance and higher values which give faster tracking. The optimum value will depend on factors related to the configuration and use of the system and is usually adjusted by trial and error. Values in the range of 0-1 and preferably in
10 the order of 0.2 have been found to be useful with the particular system described above.

The experimental results are shown in Fig. 3, showing a maximum tracking error of around $57m$. To further illustrate the effectiveness of the adaptive dither, the control results without the dither signal are shown in Fig. 4.

15 It will be appreciated by persons skilled in the art that numerous variations and/or modifications may be made to the invention as shown in the specific embodiments without departing from the spirit or scope of the invention as broadly described. The present embodiments are, therefore, to be considered in all respects as illustrative and not restrictive.

Bibliography

- 5 [1] D.M. Alter and T.C. Tsao, Control of linear motors for machine tool feed drives: design and implementation of H_∞ optimal feedback control, ASME J. of Dynamic systems. Measurement and Control, vol. 118, pp649-658, 1996.

- [2] G.Otten, T.J.A.de Vries, J.van Amerongen, A.M.Rankers and E.W.Gaal, Linear motor motion control using a learning forward controller, IEEE/ASME Trans. on Mechatronics, vol.2(3), pp179-187, 1997

- 10 [3] B. Yao and M. Tomizuka, Adaptive robust control of SISO nonlinear systems in a semi-strict feedback form, Automatica, vol. 33(5), pp.893-900, 1997.

- 15 [4] K.K. Tan, S. N. Huang, H. F. Dou, S.Y. Lim, S. J. Chin, Adaptive Robust Motion Control for Precise Trajectory Tracking Applications, Mechatronics - submitted, 1999.

- 20 [5] K.K.Tan, T.H.Lee, S.Y.Lim, and H.F.Dou, Learning enhanced motion control of permanent magnet linear motor, Proc. of the third IFAC International Workshop on Motion Control, Grenoble, France, pp397-402, 1998.



CLAIMS

1. A control system for controlling a plant having an operating characteristic which describes the translation of a plant input to a plant output, wherein the plant characteristic has a linear component and a non-linear component, the control system comprising a feedback control function, and a feed-forward control function, such that a demand signal is simultaneously applied to respective inputs of the feedback and feed-forward control functions and respective outputs of the feedback and feed-forward control functions are summed together to generate the plant input, the feed-forward control function having a first component which is a function of a model of the linear component of the plant characteristic, and a second component which is an adaptive function to compensate for the non-linear component of the plant characteristic, and the adaptive function being approximately modeled on the non-linear component of the plant characteristic and having adaptive laws which vary parameters of the adaptive function with time such that the adaptive function approaches the non-linear component of the plant characteristic.
2. The control system of claim 1 wherein the non-linear component of the plant characteristic is of the form:-

$$u_{ripple} = A(x) \sin(\omega x + \phi) = A_1(x) \sin(\omega x) + A_2(x) \cos(\omega x),$$

- where x is the plant variable,
and where the adaptive function has the form:-

$$u_{AFC} = a_1(x(t)) \sin(\omega x) + a_2(x(t)) \cos(\omega x),$$

where

$$\dot{a}_1(x(t)) = -ge \sin(\omega x),$$

$$\dot{a}_2(x(t)) = -ge \cos(\omega x),$$

e is an error signal given by:-

$$e = (x_d - x),$$

- g is an adaptation gain and is greater than 0, x_d is the desired function of the plant variable and ω is related to $1/\text{period}$ of the non-linear component of the plant characteristic, such that the adaptive feed-forward control function continuously adjusts the parameters a_1 & a_2 in response to the error signal e .



3. The system of claim 2 wherein the plant is a permanent magnet linear motor (PMLM) the plant variable x represents an instantaneous position of a translator of the linear motor, the desired function of the plant variable x_d represents the desired trajectory of the translator and the PMLM has a magnetic structure having a pole pitch x_p , such that $\omega = 2\pi / x_p$.
4. The system of claim 3 wherein the adaptation gain has a value which is greater than zero and less than or equal to one.
5. The system of claim 4 wherein the adaptation gain has a value which is less than 0.6.
- 10 6. The system of claim 5 wherein the adaptation gain has a value which is greater than or equal to 0.2.
7. The system of claim 6 wherein the adaptation gain is equal to 0.2.
8. The system as claimed in any one of claims 1 to 7 wherein the feedback controller is a PID controller as hereinbefore defined.

An Adaptive Ripple Suppression/ Compensation Apparatus for Permanent Magnet Linear Motors

5

Abstract

A ripple suppressor/compensator useful in the general area of motion control and applicable to a wide range of servomechanisms exhibiting a force ripple characteristics, including the permanent magnet linear motors. An
10 adaptive feed-forward control signal is generated which compensates for the ripple force, thus allowing for more precise tracking performance to be achieved.

15

(Figure 2 is to be published.)

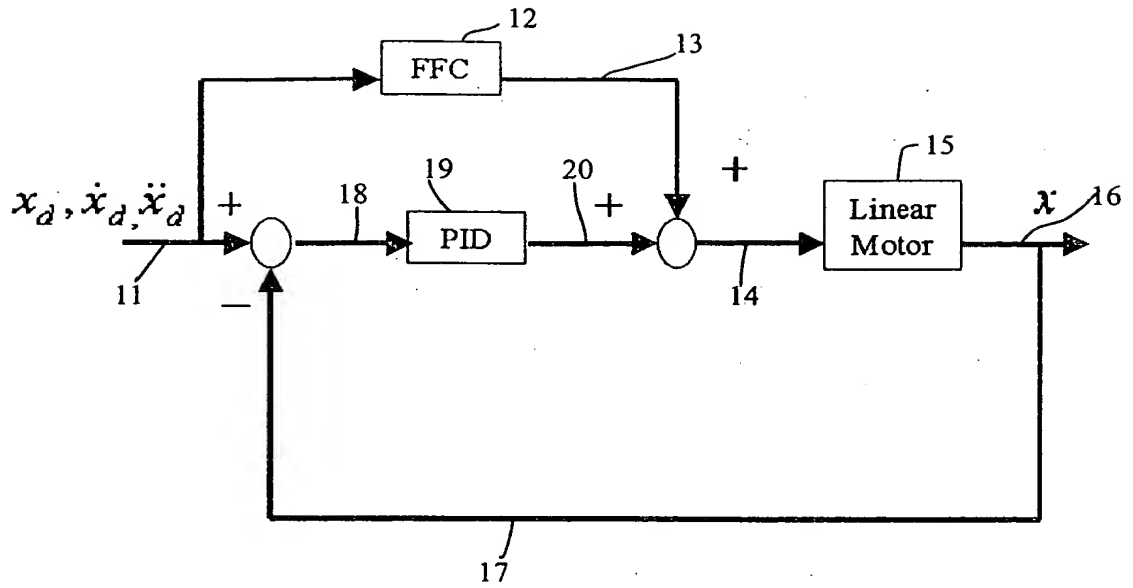


FIGURE 1

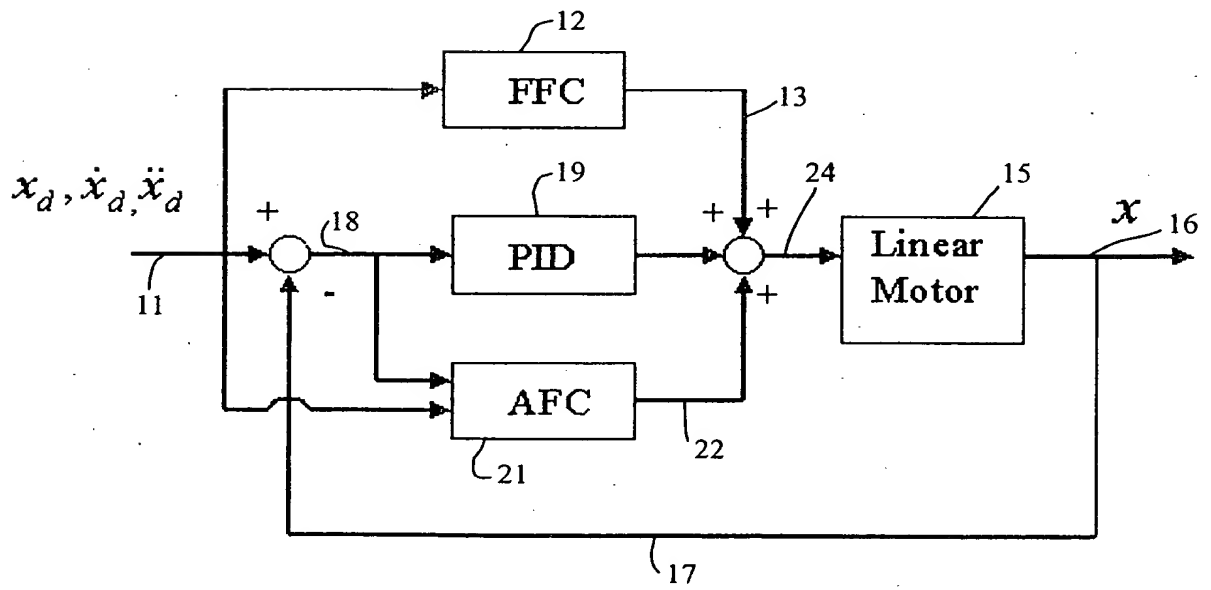


FIGURE 2

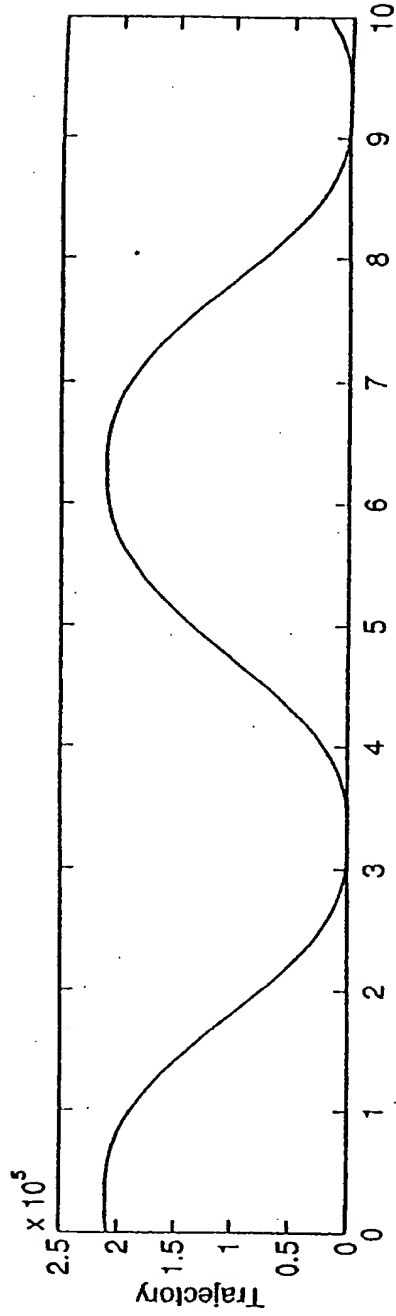


FIGURE 3(a)

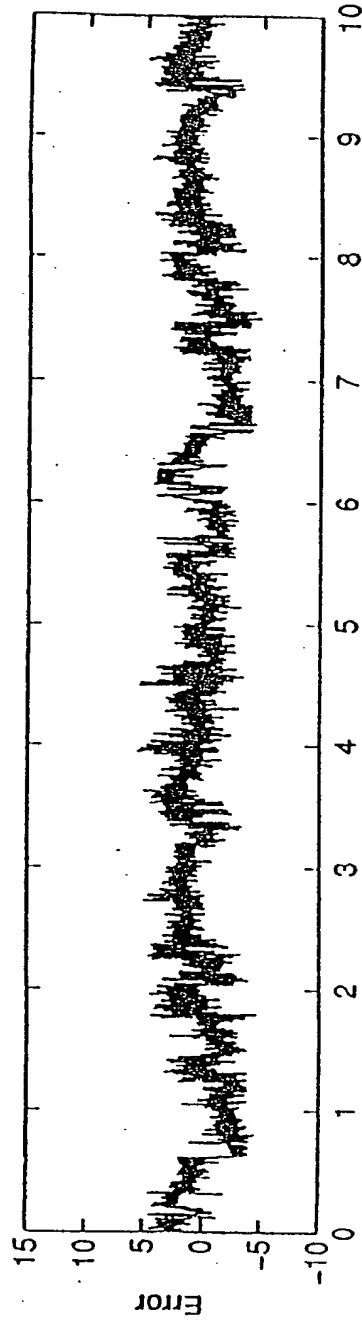


FIGURE 3(b)

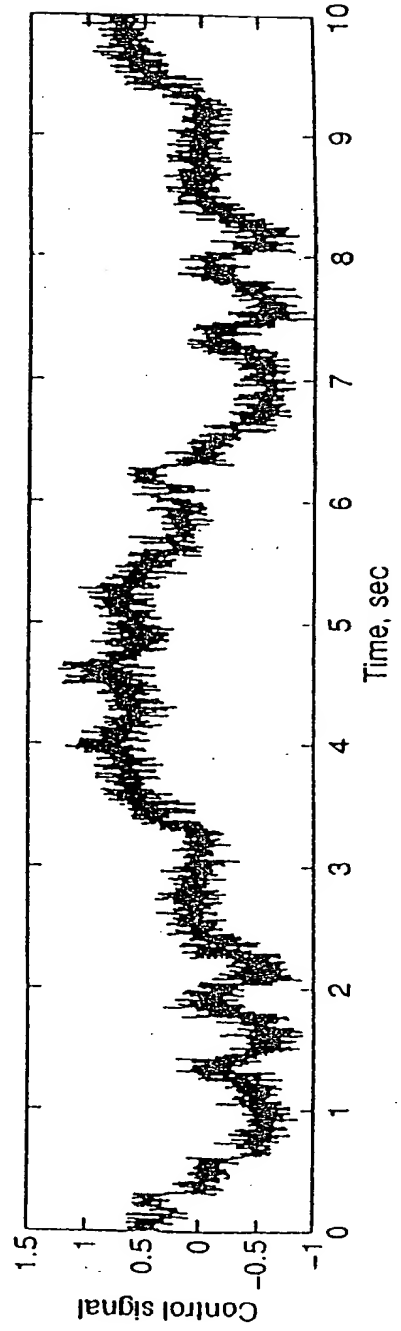


FIGURE 3(c)

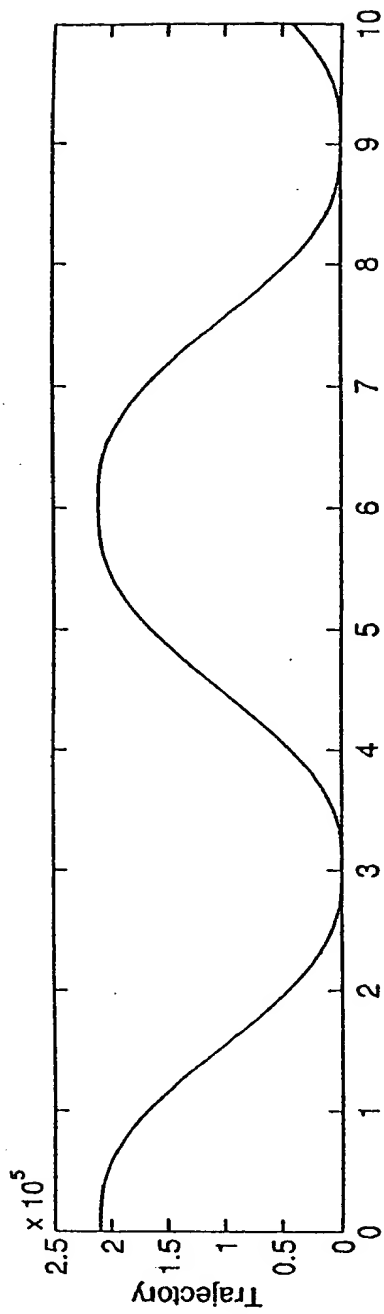


FIGURE 4(a)

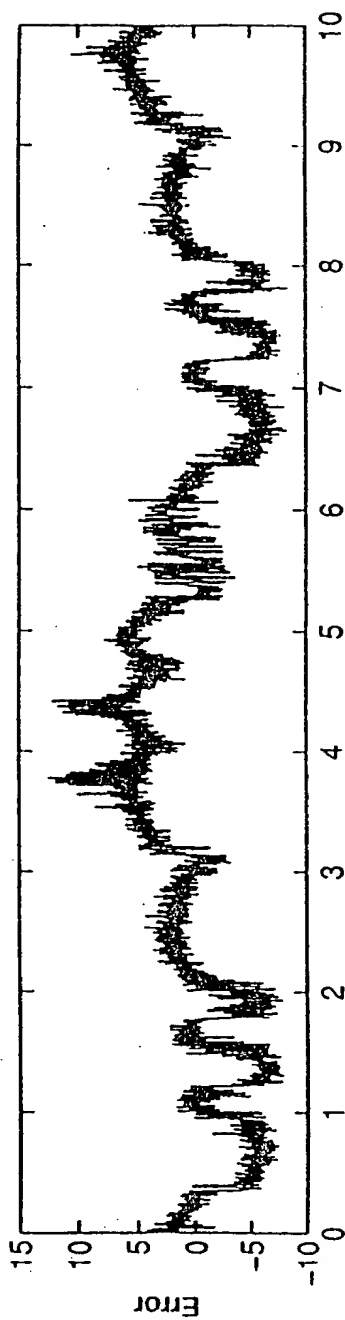


FIGURE 4(b)

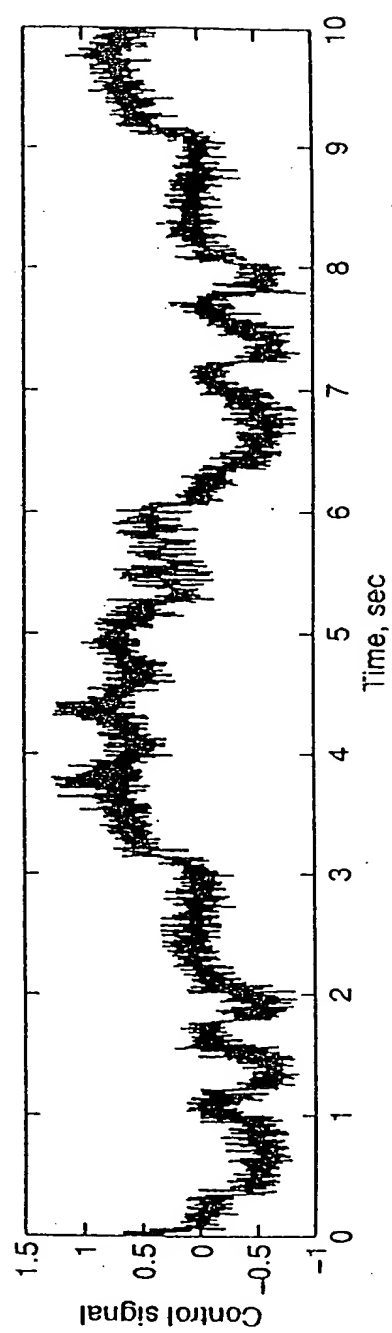


FIGURE 4(c)